

Agenda

1 Attendees

- Chair: Ben
- Facilitator: Pavi
- TimeKeeper: Sean
- Recorder: Isaac
- Sammy
- Huy Nguyen

2 Client Questions

2.1 The Rover Map

- What does the map look like, physical obstacles and lines?
- Is the starting location and orientation of the robot known?
- How much of the map do we explore?
- How is accuracy measured?
- When this DTD for the xml completed? Is there any ETA?
- Details on the starting point for partially completed maps

2.2 No Go Zones

- How are the No Go Zones intended to be selected on the UI?
- Are they represented physically or just graphically on the map?
- What is used by the operator to display the map and control the robot?
- What are the consequences of moving out side the map? or NGZ or craters?

2.3 Simulated Terrain

- How wide are the lines on the map?
- What colours/shapes indicate craters, trails?
- What is definition of mission accomplished?
- Do tracks/trails exist inside survey area or border only?
- What is the landing size?

2.4 Operation of Rover

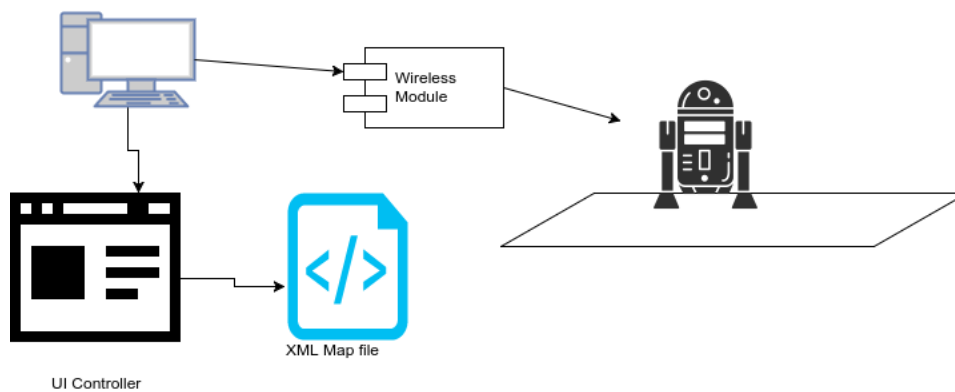
- Details on robot interfaces and sensors?
- How does the operator give commands to robot?

2.5 Safety

- What indicates an external object?
- What is the definition of a "collision" and "significant" force?

3 Initial System Overview

PG29 - Robot System Diagram



4 Negotiation

- What milestones are most important?

5 Next meeting

6 Close meeting